

AMENDMENTS TO THE CLAIMS

This listing of claims will replace all prior versions and listings of claims in the application.

Listing of Claims:

1. (Currently amended) A wall-climbing robot comprising:
 - (a) a chassis, said chassis comprising a topside and an underside;
 - (b) a rotor attached to said chassis and rotatable with respect to the chassis, said rotor comprising a radial prominence;
 - (c) a foot attached to said prominence, said foot comprising means for adhering to a surface, the means for adhering comprising a pressure sensitive adhesive; and
 - (d) an active drive means operatively connected to said rotor.
2. (Original) The wall-climbing robot of claim 1 further comprising an element attached to the underside of said chassis, said element comprising means for adhering to a surface.
3. (Original) The wall-climbing robot of claim 1 wherein said rotor further comprises a plurality of prominences.
4. (Original) The wall-climbing robot of claim 3 wherein said prominences are substantially equispaced around the rotor.
5. (Original) The wall-climbing robot of claim 3 further comprising a plurality of feet with a foot attached to each of said plurality of prominences.
6. (Original) The wall-climbing robot of claim 3, wherein said prominences are positioned at substantially equal radii around the axis of the rotor.

7. (Original) The wall-climbing robot of claim 5, wherein said feet are positioned at substantially equal radii around the axis of the rotor.
8. (Cancelled)
9. (Cancelled)
10. (Currently amended) The wall-climbing robot of claim ~~8~~1, wherein said means for adhering comprises an adhesive of polymerizing styrene, butadiene naphthenic oil, calcium carbonate, and hydrogenated polyterpene resin.
11. (Original) The wall-climbing robot of claim 1, wherein said rotor comprises a hub, a leg connected to said hub, and a foot connected to said leg.
12. (Original) The wall-climbing robot of claim 11, wherein said robot further comprises a plurality of legs and a plurality of feet.
13. (Original) The wall-climbing robot of claim 3, wherein a maximum of two prominences on said rotor are able to contact a surface at any time.
14. (Original) The wall-climbing robot of claim 5, wherein a maximum of two feet on said rotor are able to contact a surface at any time.
15. (Original) The wall-climbing robot of claim 1 further comprising a means for the remote control of said active drive means.

16. (Original) The wall-climbing robot of claim 1 wherein a foot contacts a surface over less than half of a revolution of the rotor.

17. (Currently amended) A wall-climbing robot comprising:

- (a) a chassis;
- (b) a first rotor attached to said chassis and rotatable with respect to the chassis, said first rotor comprising a first radial prominence;
- (c) a second rotor attached to said chassis and rotatable with respect to the chassis, said second rotor comprising a second radial prominence;
- (d) a first foot attached to said first radial prominence, said first foot comprising means for adhering to a surface, the means for adhering comprising a pressure sensitive adhesive, and a second foot attached to said second radial prominence, said second foot comprising means for adhering to a surface, the means for adhering comprising a pressure sensitive adhesive; and
- (e) an active drive means operatively connected to said first rotor and to said second rotor.

18. (Cancelled)

19. (Cancelled)

20. (Currently amended) The wall-climbing robot of claim ~~18~~17, wherein said means for adhering comprises an adhesive of polymerizing styrene, butadiene naphthenic oil, calcium carbonate, and hydrogenated polyterpene resin.

21. (Original) The wall-climbing robot of claim 17, wherein said first rotor comprises a first plurality of prominences and a first plurality of feet attached to said first plurality of

prominences, and said second rotor comprises a second plurality of prominences and a second plurality of feet attached to said second prominences.

22. (Original) A method of using the wall-climbing robot of claim 21, wherein no fewer than one foot on each of said first rotor and said second rotor contacts a surface at any time.

23. (Original) The wall-climbing robot of claim 21, wherein at least two feet of said first plurality of feet are able to contact a surface during a least a small arc of a revolution of said first rotor.

24. (Original) The wall-climbing robot of claim 23, wherein no more than two feet of the first plurality of feet contact a surface at any time.

25. (Original) The wall-climbing robot of claim 17 further comprising a means for the remote control of said active drive means.

26. (Currently amended) The wall-climbing robot of claim 17~~19~~ further comprising a means for the remote control of said active drive means.

27. (Original) The wall-climbing robot of claim 21, wherein said first plurality of prominences are equispaced around said first rotor.

28. (Original) The wall-climbing robot of claim 27 wherein said first plurality of feet are positioned at substantially equal radii around the axis of the first rotor.

29. (Original) The wall-climbing robot of claim 17 further comprising an axle attached to said chassis, wherein said first rotor is attached proximate to an end of said axle.

30. (Original) The wall-climbing robot of claim 29 wherein said second rotor is attached proximate to an end of said axle.

31. (Original) The wall-climbing robot of claim 17 further comprising a skid mounted to said chassis able to contact a surface.

32. (Original) The wall-climbing robot of claim 17 further comprising a roller connected to said chassis able to contact a surface.

33. (Original) The wall-climbing robot of claim 31, wherein said skid is substantially remote from said first rotor.

34. (Original) The wall-climbing robot of claim 32, wherein said roller is substantially remote from said first rotor.

35. (Currently amended) A wall-climbing robot comprising:

- (a) a chassis;
- (b) a first rotor attached to said chassis and rotatable with respect to the chassis, said first rotor comprising a first radial prominence;
- (c) a second rotor attached to said chassis and rotatable with respect to the chassis, said second rotor comprising a second radial prominence;
- (d) a first foot attached to said first radial prominence, said first foot comprising means for adhering to a surface, the means for adhering comprising a pressure sensitive adhesive,

and a second foot attached to said second radial prominence, said second foot comprising means for adhering to a surface, the means for adhering comprising a pressure sensitive adhesive; and

(e) a first active drive means operatively connected to said first rotor, and a second active drive means operatively connected to said second rotor.

36. (Cancelled)

37. (Cancelled)

38. (Currently amended) The wall-climbing robot of claim ~~36~~35, wherein said means for adhering comprises an adhesive of polymerizing styrene, butadiene naphthenic oil, calcium carbonate, and hydrogenated polyterpene resin.

39. (Original) The wall-climbing robot of claim 35, wherein said first rotor comprises a first plurality of prominences and a first plurality of feet attached to said first plurality of prominences, and said second rotor comprises a second plurality of prominences and a second plurality of feet attached to said second prominences.

40. (Original) A method of using the wall-climbing robot of claim 39, wherein no fewer than one foot on each of said first rotor and said second rotor contacts a surface at any time.

41. (Original) The wall-climbing robot of claim 39, wherein at least two feet of said first plurality of feet are able to contact a surface during a least a small arc of a revolution of said first rotor.

42. (Original) The wall-climbing robot of claim 41, wherein no more than two feet of the first plurality of feet contact a surface at any time.

43. (Original) The wall-climbing robot of claim 35 further comprising a means for the remote control of said active drive means.

44. (Currently amended) The wall-climbing robot of claim ~~35~~³⁷ further comprising a means for the remote control of said active drive means.

45. (Original) The wall-climbing robot of claim 39, wherein said first plurality of prominences are equispaced around said first rotor.

46. (Original) The wall-climbing robot of claim 45 wherein said first plurality of feet are positioned at substantially equal radii around the axis of the first rotor.

47. (Original) The wall-climbing robot of claim 35 further comprising an axle attached to said chassis, wherein said first rotor is attached proximate to an end of said axle.

48. (Original) The wall-climbing robot of claim 47 wherein said second rotor is attached proximate to an end of said axle.

49. (Original) The wall-climbing robot of claim 35 further comprising a skid mounted to said chassis able to contact a surface.

50. (Original) The wall-climbing robot of claim 35 further comprising a roller connected to said chassis able to contact a surface.

51. (Original) The wall-climbing robot of claim 49, wherein said skid is substantially remote from said first rotor.

52. (Original) The wall-climbing robot of claim 50, wherein said roller is substantially remote from said first rotor.